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#### Abstract

The invention concerns a robot apt to climb along a trestle structure, particularly the trestle of a pole for high-voltage overhead electric lines, in order to carry work-tools from the base to the top of the pole. According to the invention, the robot comprises: a main support body (1); at least one slide (7) movable along said body (1) according to a main moving axis substantially vertical and parallel to the pole surface; at least a first gripping hand (3) carried by the support body (1) and at least a second gripping hand (4) carried by the slide (7); shifting means to move said gripping hands (3,4) according to a transversal axis, substantially perpendicular to the pole surface, each gripping hand (3,4) being moreover equipped with clamping means to grip the angle bar forming an upright or a ledger of the trestle structure; at least one position sensor (2) associated to the main body (1), to acquire position data concerning the configuration of the trestle; and a processing system which controls the movements of said slide (7) and of said gripping hands (3,4), also using and/or storing the signals sent from said sensors (2).

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Go to  
the  
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**EP0401751**

Biblio

Desc

Claims

Drawing

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Go to  
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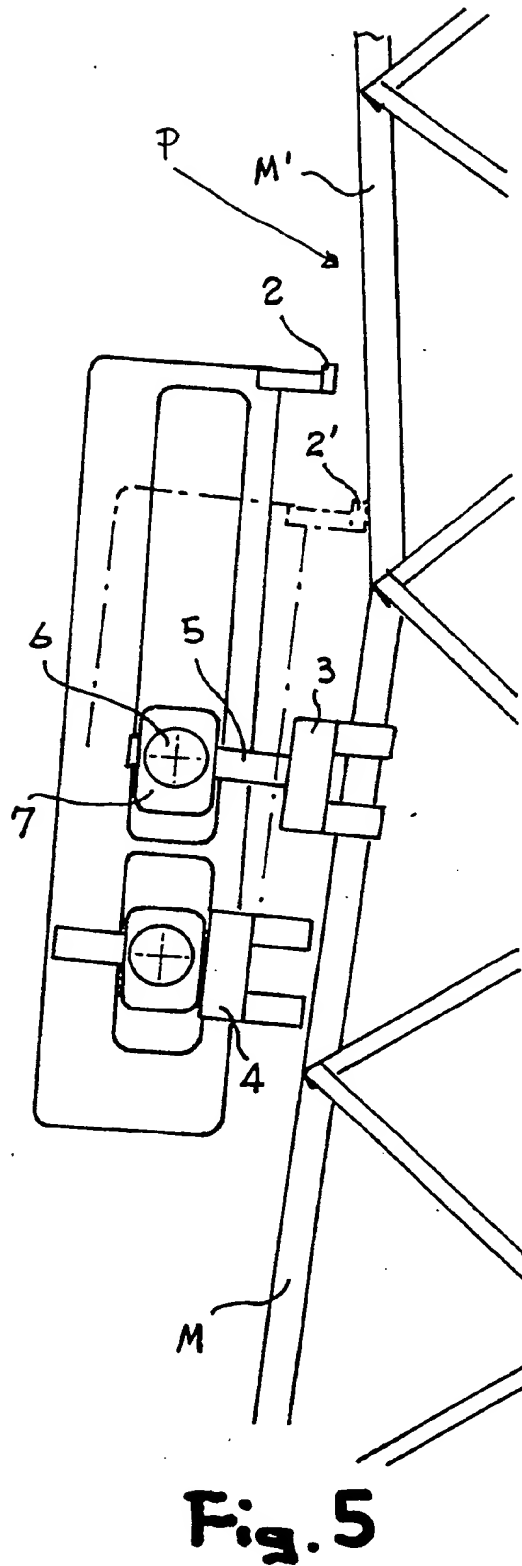
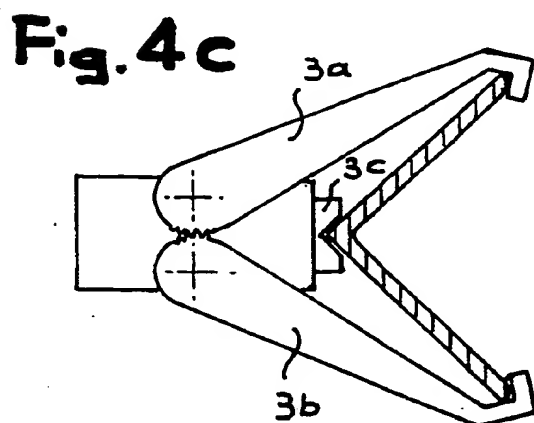
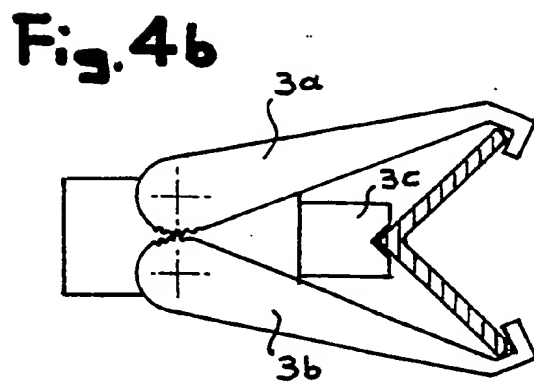
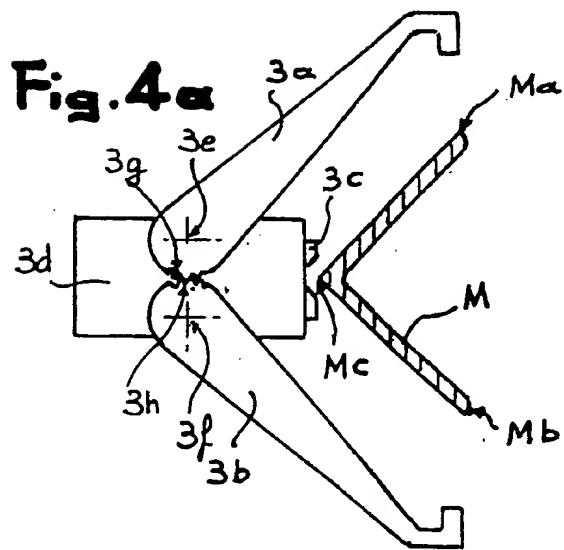
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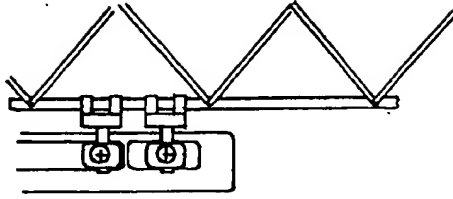
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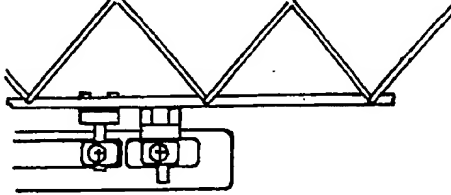




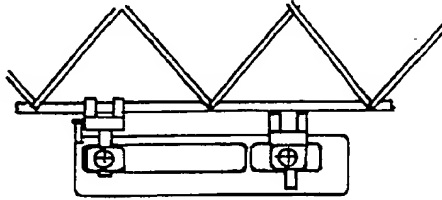
**Fig. 3g**



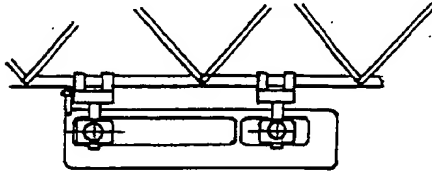
**Fig. 3f**



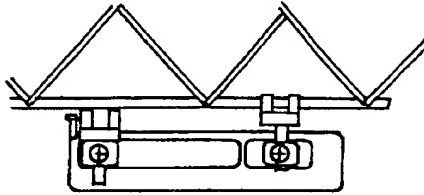
**Fig. 3e**



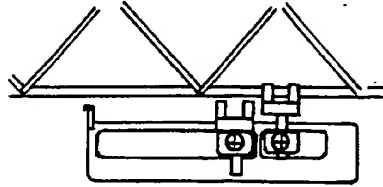
**Fig. 3d**



**Fig. 3c**



**Fig. 3b**



**Fig. 3a**

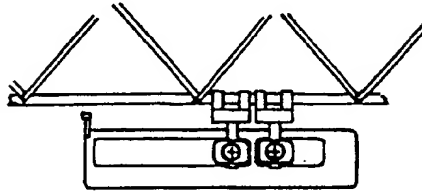


Fig. 6d

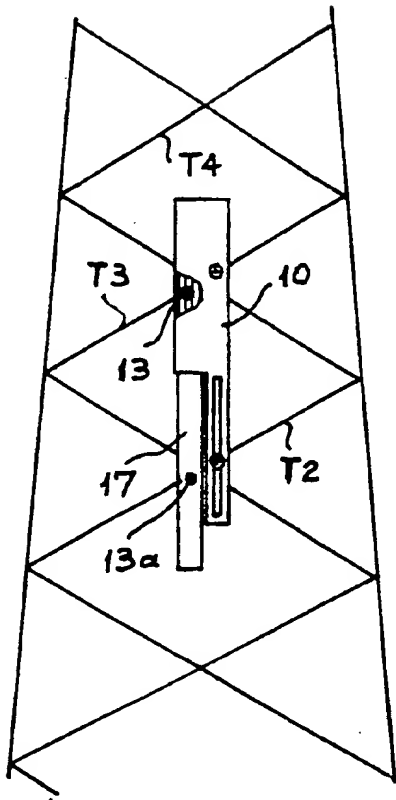
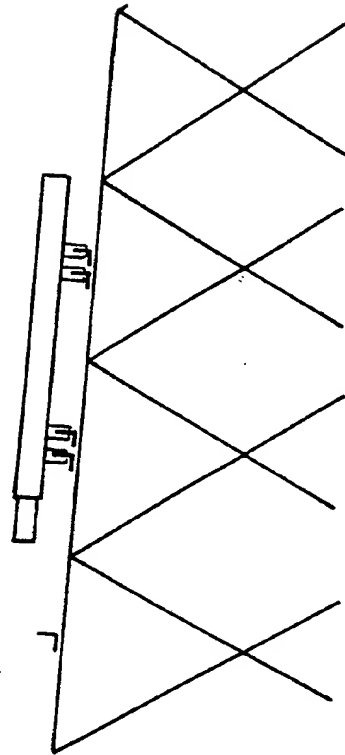


Fig. 7d



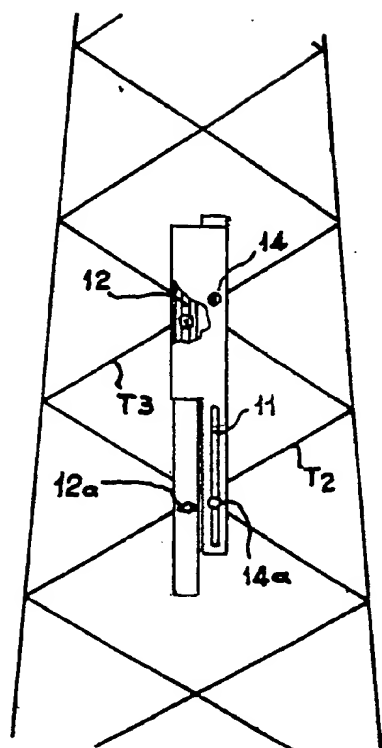


Fig. 6c

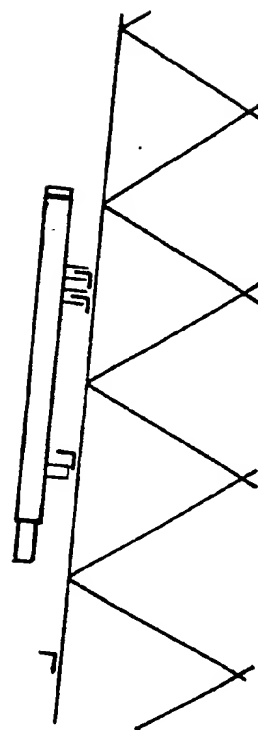


Fig. 7c



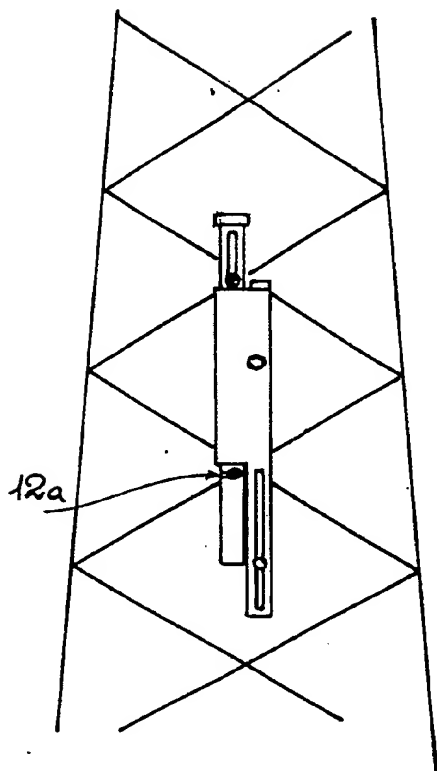


Fig. 6b

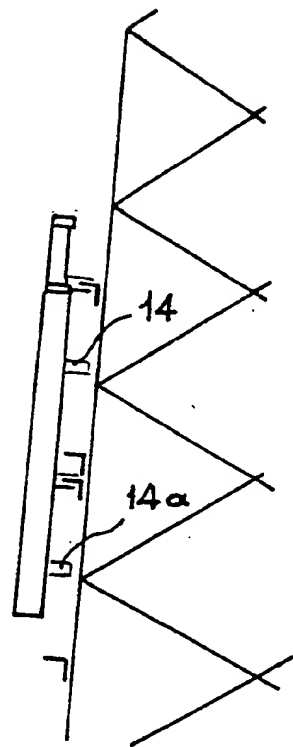


Fig. 7b

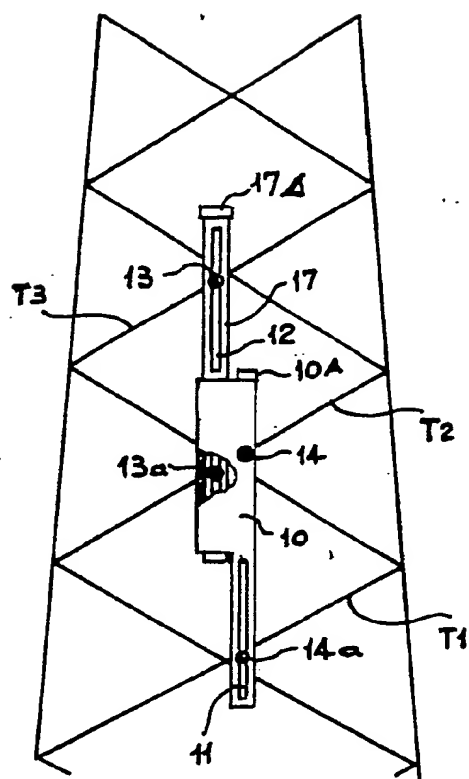


Fig. 6a

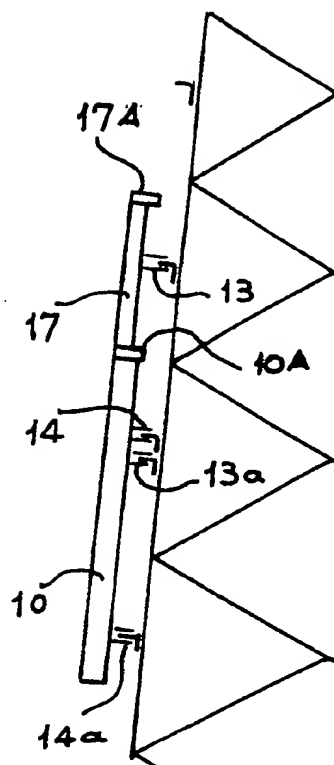
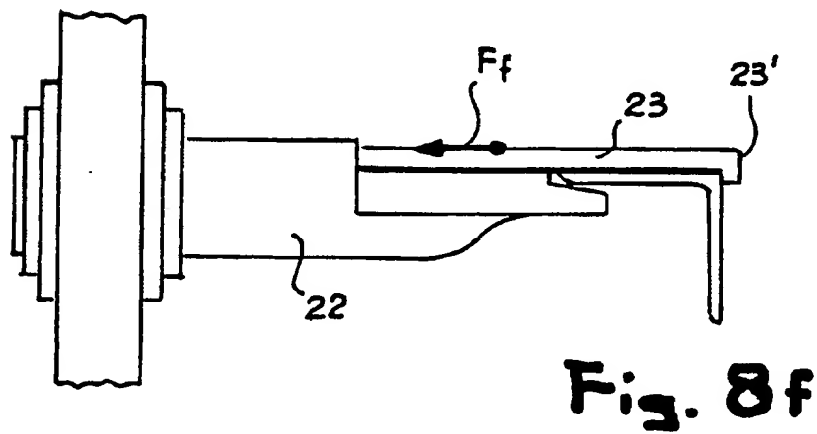
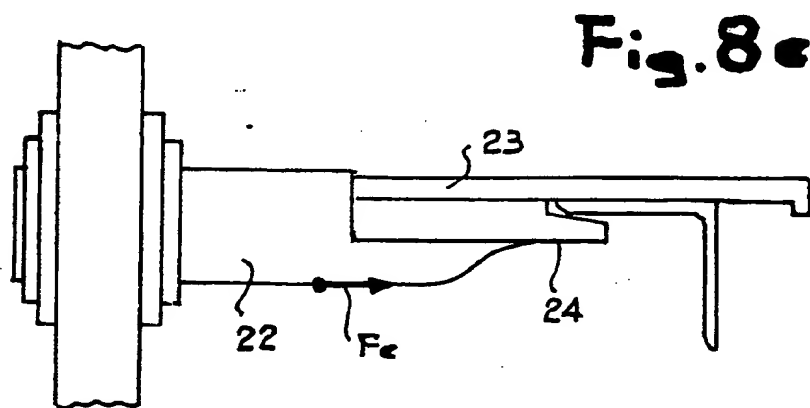
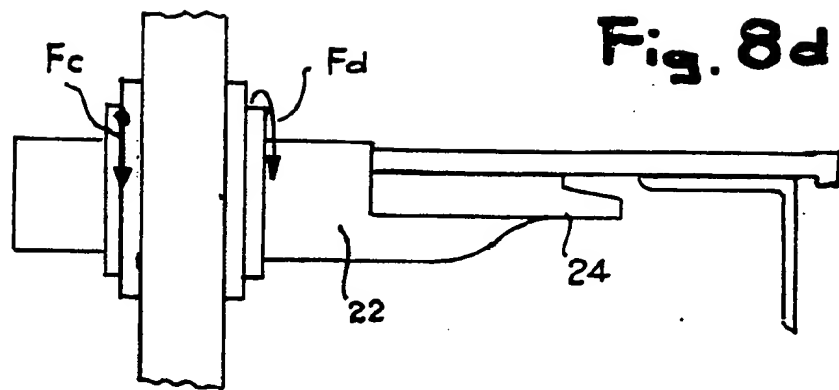
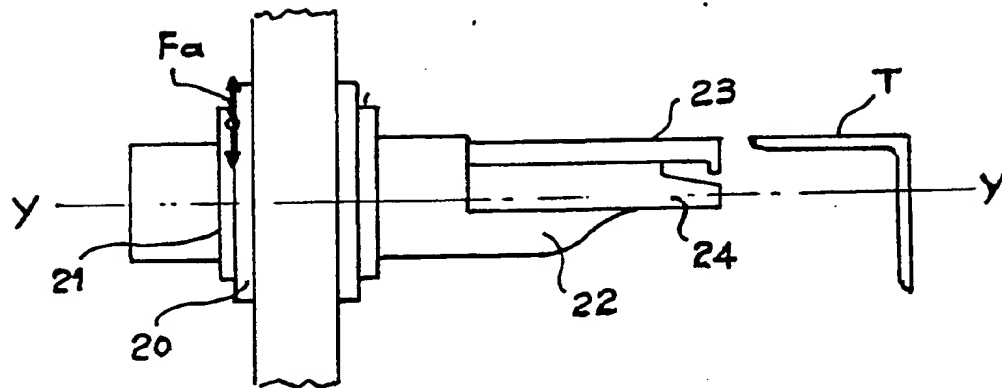


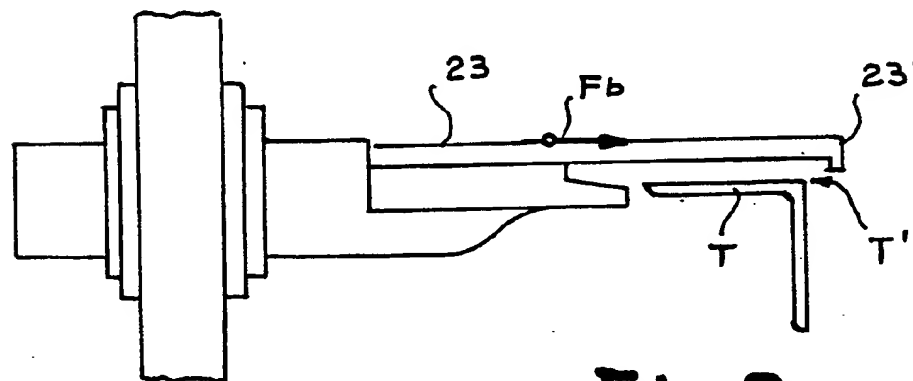
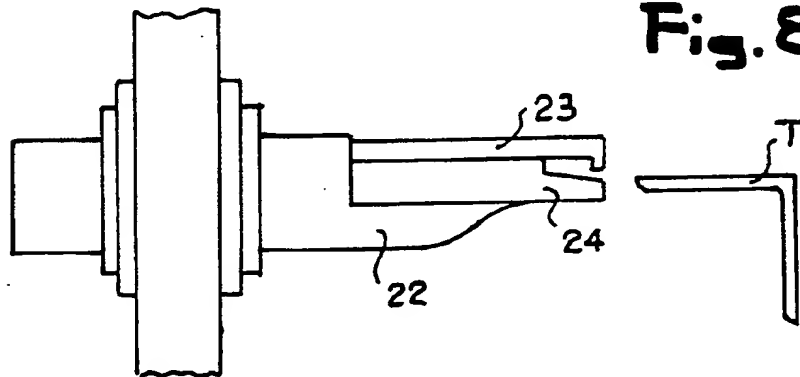
Fig. 7a



**Fig. 8a**



**Fig. 8b**



**Fig. 8c**